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(12) **EUROPEAN PATENT APPLICATION**

(21) Application number: 82100900.8  
 (22) Date of filing: 08.02.82  
 (51) Int. Cl.<sup>3</sup>: **F 16 H 39/44**  
 //E02F9/12

<p>(35) Priority: 10.02.81 JP 17468/81 10.02.81 JP 17469/81</p> <p>(43) Date of publication of application: 18.08.82 Bulletin 82/33</p> <p>(54) Designated Contracting States: DE FR</p> <p>(71) Applicant: HITACHI CONSTRUCTION MACHINERY CO., LTD. 2-10, Uchikanda-1-chome Chiyoda-ku Tokyo(JP)</p>	<p>(72) Inventor: Aoyagi, Yukio 1828-4-405, Oaza Niihari Chiyodamura Niihari-gun Ibaraki-ken(JP)</p> <p>(72) Inventor: Izumi, Eiki 2613-343, Oaza Shimoinayoshi Chiyodamura Niihari-gun Ibaraki-ken(JP)</p> <p>(72) Inventor: Yamaguchi, Takeshi 3-13, Otsutominami-2-chome Tsuchiura-shi(JP)</p> <p>(72) Inventor: Tanaka, Sotaro 24-19, Kariya-5-chome Ushikucho Inashiki-gun Ibaraki-ken(JP)</p> <p>(74) Representative: Patentanwälte Beetz sen. - Beetz jr. Timpe - Siegfried - Schmitt-Fumian Steinsdorfstrasse 10 D-8000 München 22(DE)</p>
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(54) Hydraulic drive system having a plurality of prime movers.

(57) A hydraulic drive system including at least one hydraulic actuator (7a, 7b), two variable displacement hydraulic pumps (3a, 3b) each connected to the hydraulic actuator to form a closed circuit therewith and connected in parallel with each other, two prime movers (1a, 1b) each driving one of the hydraulic pumps, and directional control valves (21a, 21b) each arranged between the hydraulic actuators and one of the hydraulic pumps. The directional control valves (21a, 21b) are each operative to shut, when one of the prime movers associated therewith is shut down, the hydraulic pump connected to the shutdown prime mover off the other hydraulic pump and the hydraulic actuator, to thereby prevent the hydraulic pump from being rotated by the pressure fluid delivered by the other hydraulic pump.

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FIG. 1

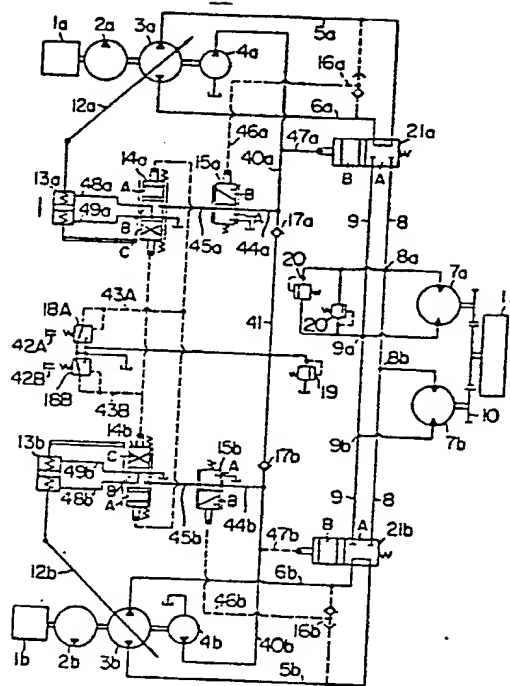
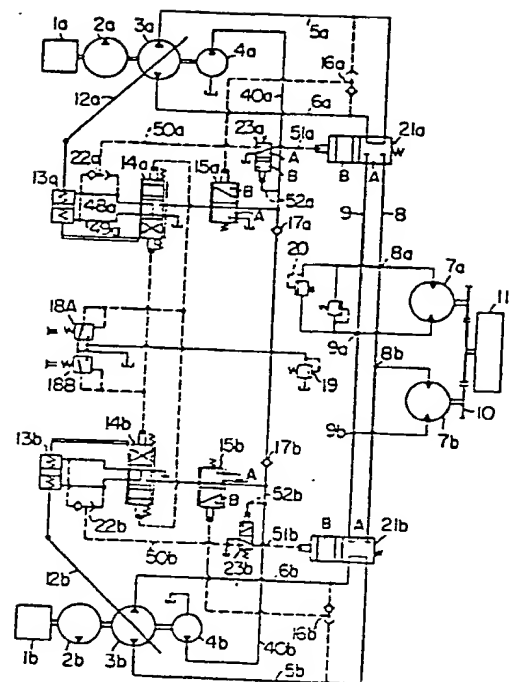


FIG. 2



HYDRAULIC DRIVE SYSTEM HAVING A PLURALITY  
OF PRIME MOVERS

1 BACKGROUND OF THE INVENTION

This invention relates to a hydraulic drive system comprising at least one hydraulic actuator, a plurality of hydraulic pumps connected in parallel  
5 with one another and each connected to said actuator to form a closed circuit therewith, and a plurality of prime movers each for driving the plurality of hydraulic pumps, which is suitable for driving a hydraulic shovel of a large size, for example.

10 In the field of civil engineering machinery, such as hydraulic shovels, for example, a hydraulic drive system is known which comprises a single variable displacement hydraulic pump connected to one or a plurality of hydraulic actuators to form a closed circuit  
15 therewith. In this hydraulic drive system, operation of the actuators is controlled by controlling the direction in which the pump delivers pressure fluid and the flow rate of the delivered pressure fluid without using a directional control valve mounted  
20 between the hydraulic pump and the actuators. In recent years, a hydraulic drive system has come into use which, to cope with an increase in the size of hydraulic shovels and hence an increase in the size of the hydraulic actuators, comprises two variable  
25 displacement hydraulic pumps connected in parallel

1 with each other and each connected to hydraulic actuators  
to form a closed circuit therewith. The two hydraulic  
pumps are driven by separate prime movers, and operation  
of the actuators is controlled by controlling the  
5 direction in which the two hydraulic pumps deliver the  
pressure fluid and the flow rate of the delivered  
pressure fluid by the pumps with a common operation  
signal.

In the hydraulic drive system comprising  
10 two hydraulic pumps and two prime movers, the pressure  
fluid delivered by the two hydraulic pumps can be  
used in good condition for operating the actuator so  
long as the two prime movers normally operate. However,  
when one of the prime movers is shut down for some  
15 reason, there is the risk that the pressure fluid  
delivered by the hydraulic pump connected to the  
normally operating prime mover is supplied to the  
other hydraulic pump and might cause same to rotate  
in the reverse direction, or the hydraulic pump might  
20 perform the function of a motor to thereby cause  
the prime mover connected to the hydraulic pump and  
other pumps connected to the prime mover, such as,  
lubricant pump, pilot pump and hydraulic pump for  
other hydraulic circuit, etc. to rotate in the reverse  
25 direction, to thereby cause damage thereto.

#### SUMMARY OF THE INVENTION

An object of this invention is to provide

1 a novel hydraulic drive system comprising a plurality  
of variable displacement hydraulic pumps connected in  
parallel with each other and connected to at least  
one hydraulic actuator, and a plurality of prime movers  
5 each driving the plurality of hydraulic pumps, wherein  
the prime mover not in normal operating condition can  
be prevented from being forcedly rotated by the variable  
displacement hydraulic pump connected thereto which  
might function as a hydraulic motor.

10 Another object of the present invention is  
to provide a hydraulic drive system of the type described  
which is provided with means for fluidly cutting the  
hydraulic pump connected to the prime mover not in  
normal operating condition off the other hydraulic  
15 pump and the hydraulic actuator or actuators.

Still another object of the invention is to  
provide a hydraulic drive system of the type described  
which is capable, when the hydraulic actuator is  
stopped or when the flow rate of the pressure fluid  
20 delivered by the hydraulic pumps is zero (0), of  
fluidly cutting the hydraulic actuator off the hydraulic  
pumps, to thereby positively keep the hydraulic actuator  
in the stopped condition.

Other and additional objects, features and  
25 advantages of the invention will become more apparent  
from the description set forth hereinafter when  
considered in conjunction with the accompanying drawings.

1 BRIEF DESCRIPTION OF THE DRAWINGS

Fig. 1 is a hydraulic circuit diagram showing one embodiment of the hydraulic drive system in conformity with the invention;

5 Fig. 2 is a hydraulic circuit diagram showing another embodiment of the hydraulic drive system in conformity with the invention;

Fig. 3 is a sectional view, on an enlarged scale, of the control cylinder used in the system shown  
10 in Fig. 2;

Figs. 4 and 5 are hydraulic circuit diagrams showing modifications of the directional control valve 21a used in the system shown in Fig. 2;

Fig. 6 is a hydraulic circuit diagram showing  
15 still another embodiment distinct from the embodiments shown in Figs. 1 and 2;

Fig. 7 is a flow chart of the arithmetic unit used in the system shown in Fig. 6; and

Fig. 8 is a graph used for reading out  $\Delta Y$   
20 in steps S12 and S14 of the flow chart shown in Fig. 7.

DETAILED DESCRIPTION OF THE PREFERRED EMBODIMENTS

Fig. 1 shows the hydraulic drive system comprising one embodiment of the invention for driving  
25 a single load 11. The hydraulic drive system comprises two hydraulic actuators or motors 7a and 7b drivingly connected to the load 11 via a gearing 10, two variable displacement hydraulic pumps 3a and 3b, and prime

1 movers 1a and 1b for driving the hydraulic pumps 3a  
and 3b. In addition to the hydraulic pumps 3a and 3b,  
hydraulic pumps 2a and 2b for another hydraulic drive  
system and pilot pumps 4a and 4b for producing control  
5 pressures are also driven by the two prime movers 1a  
and 1b. The one variable displacement hydraulic pump  
3a is connected through main lines 5a and 6a, a directional  
control valve 21a and main lines 8 and 9 to the two  
hydraulic motors 7a and 7b to form closed circuits  
10 therewith respectively, and the other variable displacement hydraulic pump 3b is also connected through main  
lines 5b and 6b, a directional control valve 21b and  
the main lines 8 and 9 to the two hydraulic pumps 7a  
and 7b to form closed circuits therewith respectively.  
15 Stated differently, the one hydraulic motor 7a has  
connected thereto the two hydraulic pumps 3a and 3b  
which are connected in parallel with each other at  
parallel connection points 8a and 9a, and the other  
hydraulic motor 7b has connected thereto the two  
20 hydraulic pumps 3a and 3b which are connected in parallel with each other at parallel connection points 8b  
and 9b. Overload relief valves 20 are mounted between  
the main lines 8 and 9 for setting the highest pressure  
for the main lines. The directional control valves  
25 21a and 21b are for selectively shutting the associated  
hydraulic pumps 3a and 3b off the hydraulic motors  
and other hydraulic pumps and their details will be  
described later.

1           The variable displacement hydraulic pumps  
may be in the form of plunger pumps provided with  
means 12a and 12b respectively for varying the displace-  
ment volume, such as a swash plate or eccentric shaft.  
5   The displacement volume varying means 12a and 12b have  
connected thereto known regulators comprising control  
cylinders 13a and 13b, servo valves 14a and 14b and  
cut-off valves 15a and 15b respectively. The one  
control cylinder 13a is connected through the servo  
10 valve 14a and cut-off valve 15a to a control pressure  
line 40a connected to the pilot pump 4a, to receive  
a supply of pressure fluid from the pump 4a. The  
other control cylinder 13b is connected through the  
servo valve 14b and cut-off valve 15b to a control  
15 pressure line 40b connected to the pilot pump 4b, to  
receive a supply of pressure fluid from the pump 4b.  
The lines 40a and 40b are connected to a common control  
pressure line 41 through check valves 17a and 17b  
respectively. The line 41 has connected thereto a  
20 relief valve 19 to keep the pressures in the lines  
40a, 40b and 41 from exceeding a predetermined adjusted  
value.

          The servo valves 14a and 14b are pilot-  
operated, three-position valves and movable between  
25 opposite extreme positions A and C and a normal neutral  
position B. The servo valves 14a and 14b have movable  
sleeves connected to pistons of the control cylinders  
13a and 13b respectively. A pair of manually-operated



1 pilot valves 18A and 18B supply pilot pressures to  
the servo valves 14a and 14b respectively. The pilot  
valves 18A and 18B are variable reduce valves inputting  
an adjusted pressure from the line 41 and supply to  
5 output lines 43A and 43B a pressure proportional to  
the manipulated variable of manually-operated levers  
42A and 42B. The one output line 43A is connected  
to the two servo valves 14a and 14b in a manner to  
apply pressure thereto to shift same to position A,  
10 and the other output line 43B is connected thereto  
to apply pressure thereto to shift same to position C.  
Thus the two servo valves 14a and 14b are simultaneously  
actuated by one manually-operated valve 18A or 18B.

The cut-off valve 15a is a pilot-operated,  
15 two-position valve and movable between a normal position  
A in which it allows lines 44a and 45a to communicate  
with each other and a position B in which it releases  
pressure fluid from the line 45a. The cut-off valve  
15a receives as a pilot pressure a higher main line  
20 pressure through a shuttle valve 16a arranged between  
the main lines 5a and 6a and a line 46a. The other  
cut-off valve 15b is also a pilot-operated, two-position  
valve and movable between a normal position A in which  
it allows lines 44b and 45b to communicate with each  
25 other and a position B in which it releases pressure  
fluid from the line 45b. The cut-off valve 15b receives  
as a pilot pressure a higher main line pressure  
through a shuttle valve 16b arranged between the

- 1 main lines 5b and 6b and a line 46b.

The directional control valves 21a and 21b located in the main lines will now be described in detail. The directional control valve 21a is a pilot-  
5 operated, two-position valve having two input ports connected to the main lines 5a and 6a on the hydraulic pump 3a side and two output ports connected to the main lines 8 and 9 on the hydraulic motor side. The valve 21a is movable between a normal position A to which  
10 it is biased by a spring and a position B to which it is switched by a pilot pressure. When the valve 21a is in position A, the two input ports are brought into communication with each other and the two output  
15 ports are individually blocked. When it is in position B, the two input ports are in communication with the output ports respectively. The valve 21a receives a pilot pressure through a line 47a from the line 40a which receives a supply of pressure fluid from the  
20 pilot pump 4a. The directional control valve 21b, which is of the same construction as the directional control valve 21a, receives a pilot pressure through a line 47b from the line 40b which receives a supply of  
25 pressure fluid from the pilot pump 4b. The directional control valves 21a and 21b each move to position B under the influence of a predetermined adjusted pressure which is produced by the pilot pumps 4a and 4b in the lines 40a, 40b and 41, when the prime movers 1a and 1b normally operate. However, when the pressure in the

1 lines 40a and 40b drops to a predetermined value as  
the result of a reduction of the rotational speed of  
the prime movers 1a and 1b to a predetermined level  
below the normal rotational speed, the valves 21a and  
5 21b are moved to the normal position A by the biasing  
force of the spring.

Operation of the hydraulic drive system of  
the aforesaid construction will be described. Assume  
that the prime movers 1a and 1b are both operating  
10 normally. This causes a predetermined adjusted pressure  
to be generated by the relief valve 19 in the lines 40a,  
40b and 41. With the adjusted pressure acting on the  
directional control valves 21a and 21b through the lines  
47a and 47b, the valves 21a and 21b are both in position  
15 B to bring the main lines 5a, 6a, 5b and 6b into  
communication with the main lines 8 and 9. Meanwhile  
when the pilot valves 18A and 18B are inoperative, no  
pressure is generated in the output lines 43A and 43B  
thereof, so that the servo valves 14a and 14b are both  
20 in normal position B and pistons of the control cylinders  
13a and 13b and the displacement volume varying means  
12a and 12b connected thereto are in neutral position.  
Thus the flow rates of pressure fluid delivered by  
the pumps 3a and 3b are both zero (0), so that the  
25 hydraulic motors 7a and 7b remain inoperative.

Assume that the operation lever 42A of one  
pilot valve 18A is manipulated when the parts of the  
system are in the aforesaid condition. A displacement

1 of the operation lever 42A causes a pressure commensurate with the displacement to be generated in the output line 43A. The pressure in the output line 43A acts on the servo valves 14a and 14b and causes their  
5 spools to shift downwardly and upwardly respectively for an amount corresponding to the pressure in the line 43A. The downward shift of the valve spool of the servo valve 14a enables the pressure in the line 40a to be supplied to an upper space of the control cylinder  
10 13a through a line 48a, to thereby shift downwardly the piston in the cylinder 13a. The downward shift of the piston actuates the displacement volume varying means 12a, to cause the hydraulic pump 3a to begin to deliver pressure fluid to the main line 5a. The shift  
15 of the piston being fed back to the sleeve of the servo valve 14a, the piston comes to a halt after moving a distance corresponding to the distance covered by the movement of the valve spool of the servo valve 14a. Thus the flow rate of the pressure fluid delivered  
20 by the hydraulic pump 3a has a value which is commensurate with the distance covered by the movement of the valve spool or the amount of displacement of the operation lever 42A of the pilot valve 18A. Likewise, the upward shift of the servo valve 14b actuates the  
25 displacement volume varying means 12b of the hydraulic pump 3b, to cause the hydraulic pump 3b to begin to deliver to the main line 5b a supply of pressure fluid at a flow rate commensurate with the amount of

1 displacement of the operation lever 42A. The pressure  
fluid from the hydraulic pumps 3a and 3b flows through  
the main lines 5a and 5b into the common main line 8  
and actuates the hydraulic motors 7a and 7b to drive  
5 the load 11. After actuating the hydraulic motors  
7a and 7b, the pressure fluid flows into the main  
line 9 from which it is returned to the hydraulic pumps  
3a and 3b via the main lines 6a and 6b respectively.  
In the process in which the flow rate of the pressure  
10 fluid delivered by the hydraulic pumps 3a and 3b in-  
creases following up the operation of the pilot valve  
18A, the number of revolutions of the hydraulic motors  
7a and 7b might not be able to increase quickly when  
the load 11 has high inertia. In such a case, the  
15 pressure in the main lines 5a and 5b on the discharge  
side rises. When this pressure reaches a predetermined  
pressure level for switching the cut-off valves 15a  
and 15b, the valves 15a and 15b move from normal po-  
sition A to position B to reduce the flow rate and  
20 the pressure of the pressure fluid supplied to the  
control cylinders 13a and 13b through the servo valves  
14a and 14b. Thus the displacement volume of the variab  
displacement hydraulic pumps 3a and 3b is adjusted in  
reverse, to thereby reduce the pressure in the main  
25 lines on the higher pressure side. As the aforesaid  
operation is repeated, the flow rate of the pressure  
fluid delivered by the hydraulic pumps 3a and 3b slowly  
changes to the amount corresponding to that of

1 manipulation of the pilot valve 18A while the pressure  
in the main lines on the higher pressure side is being  
restricted to a level below the level set for switching  
the cut-off valves 15a and 15b.

5 When the other pilot valve 18B is actuated,  
the hydraulic pumps 3a and 3b deliver pressure fluid  
to the main lines 6a and 6b respectively, to thereby  
rotate the hydraulic motors 7a and 7b in a direction  
opposite the direction in which they are rotated when  
10 the one pilot valve 18A is actuated.

As afore-mentioned, the hydraulic pumps 3a  
and 3b are simultaneously controlled by the pilot  
valves 18A and 18B, to thereby actuate the hydraulic  
motors 7a and 7b, in case where both prime movers 1a  
15 and 1b are normally operating. During operation of  
the system, it is possible to occur that one of the  
prime movers is shut down for some reason. For example,  
in the event that the one prime mover 1a has its output  
inordinately lowered when the pilot valve 18A is  
20 actuated to increase the flow rate of the pressure  
fluid delivered by the hydraulic pumps 3a and 3b, the  
prime mover 1a may be shut down due to an increase in  
the load applied thereto by the increase in the pressure  
fluid delivered by the pump 3a. When this is the case,  
25 the pilot pump 4a connected to the prime mover 1a  
will stop rotating, and its delivery pressure or the  
pressure of the line 40a will drop. A drop in the  
pressure in the lines 40a allows the directional control

1 valve 21a to move to position A, thereby shutting the  
hydraulic pump 3a off the hydraulic motors 7a and 7b  
and the other hydraulic pump 3b. Thus the hydraulic  
motors 7a and 7b are operated only by the pressure fluid  
5 from the hydraulic pump 3b. Since the pressure fluid  
from the hydraulic pump 3b is prevented from flowing to  
the hydraulic pump 3a by the directional control valve  
21a, the variable displacement hydraulic pump 3a is  
prevented from functioning as a hydraulic motor by  
10 using the pressure fluid from the pump 3b, so that the  
prime mover 1a is prevented from being rotated by the  
pump 3a functioning as a hydraulic motor. When the  
directional control valve 21a shifts from position B  
to position A, a small volume of pressure fluid may  
15 be delivered by the hydraulic pressure pump 3a. This  
raises no problem because the pressure fluid delivered  
in this way is returned to the suction port of the pump  
3a through the control valve 21a in position A.

After the prime mover 1a is shut down, the  
20 control pressure applied to the control cylinder 13a  
or the pressure in the line 40a becomes zero (0), so  
that the piston of the control cylinder 13a returns  
to a neutral position and comes to a halt irrespective  
of the position of the servo valve 14a. Meanwhile  
25 the other prime mover 1b continues its normal operation  
and the normal adjusted pressure is applied by the  
pilot pump 4b to the lines 40b and 41, so that the  
hydraulic pump 3b is normally controlled by the pilot

1 valves 18A and 18B and the hydraulic motors 7a and 7b  
are driven by the pressure fluid supplied by the  
hydraulic pump 3b.

From the foregoing description, it will be  
5 appreciated that in the embodiment shown and described  
hereinabove, when the number of revolutions of one of  
the prime movers 1a and 1b drops below a predetermined  
rpm lower than its normal rpm range, or at the time  
it is shut down or it rotates in the reverse direction,  
10 one of the directional control valves 21a and 21b shifts  
to position A to shut the hydraulic pump 3a or 3b  
connected to the disabled prime mover off the other  
hydraulic pump and hydraulic motors. Thus the hydraulic  
pump connected to the disabled prime mover is prevented  
15 from receiving pressure fluid from the other hydraulic  
pump to function as a hydraulic motor and impart rota-  
tion to the prime mover connected thereto.

Fig. 2 shows another embodiment of the  
invention in which parts similar to those shown in  
20 Fig. 1 are designated by like reference characters.  
This embodiment also comprises the pilot-operated  
directional control valves 21a and 21b mounted between  
the main lines 5a and 6a and main lines 8 and 9 and  
between the main lines 5b and 6b and the main lines  
25 8 and 9 respectively. The valves 21a and 21b are of  
the same construction as those shown and described  
by referring to the embodiment shown in Fig. 1, but  
the channel through which a pilot pressure is supplied



1 is distinct from the channel through which a pilot pressure is supplied by the counterparts shown in Fig. 1. More specifically, the valve 21a receives a pilot pressure through a shuttle valve 22a mounted  
5 between two lines 48a and 49a connected to the control cylinder 13a for taking out a higher pressure, a line 50a, a pilot-operated change-over valve 23a and a line 51a. The change-over valve 23a is movable between a normal position A in which it releases pressure fluid  
10 from the line 51a and a position B in which it allows the lines 50a and 51a to communicate with each other, and the pilot pressure is supplied from the line 40a through a line 52a. Likewise, the directional control valve 21b receives a pilot pressure through a shuttle  
15 valve 22b, a line 50b, a change-over valve 23b and a line 51b, the change-over valve 23b receiving a pressure from the line 40b through a line 52b. The change-over valves 23a and 23b return to normal position A when the number of revolutions of the prime movers 1a and  
20 1b drops to a predetermined level lower than the normal rpm thereof and the pressure in the lines 40a and 40b shows a corresponding drop. As shown in Fig. 3, the control cylinder 13a has neutral position restoring springs 56 and 57 and movable spring seats 58 and 59  
25 located in pressure chambers 54 and 55 respectively. The spring seats 58 and 59 are forced against shoulders 60 and 61 respectively of the cylinder body when the piston is in a neutral position. A predetermined

1 preload is applied to the springs 56 and 57 when the  
piston is in the neutral position as shown. When the  
pressure differential between the two pressure chambers  
54 and 55 exceeds the preload applied to the springs  
5 56 or 57, the piston is allowed to move. The preload  
applied to the springs 56 and 57 is set at a level  
such that a pressure high enough to shift the control  
valve 21a to position B is generated in the pressure  
chamber 54 or 55 before the piston begins to move from  
10 the neutral position. The control cylinder 21b is of  
the same construction as the control cylinder 21a.  
Other parts of the embodiment shown in Fig. 2 are  
similar to those of the embodiment shown in Fig. 1,  
so that their description will be omitted.

15 While both prime movers 1a and 1b are normally  
operating, a predetermined adjusted pressure is generated  
in the control pressure lines 40a, 40b and 41 by the  
pilot pumps 4a and 4b, and the change-over valves 23a  
and 23b are shifted to position B by the pressure in  
20 the lines 40a and 40b to allow the lines 50a and 50b  
to communicate with the lines 51a and 51b respectively.  
When the pilot valves 18A and 18B are neutral in  
position without being manipulated, the servo valves  
14a and 14b and the pistons of the control cylinders  
25 13a and 13b are also neutral in position, so that the  
delivery by the hydraulic pumps 3a and 3b is zero  
(0). At this time, the lines 48a and 49a and lines  
48b and 49b connected to the pressure chambers of

1 the cylinders 13a and 13b respectively have the pressure  
discharged therefrom, so that no pilot pressure is  
supplied to the control valves 21a and 21b and the  
velves 21a and 21b are in normal position A. Because  
5 of this, the main lines 8 and 9 connected to the hydraulic  
motors 7a and 7b are closed at their ends. Thus the  
hydraulic motors 7a and 7b are prevented from being  
rotated by an external force exerted on the load 11  
when they are shut down, to ensure that the hydraulic  
10 motors 7a and 7b and the load 11 are kept stopped  
without being operated by an external force.

To actuate the hydraulic motors 7a and 7b  
in the aforesaid condition, the pilot valve 18A or  
18B are actuated. Actuation of the pilot valves 18A  
15 and 18B controls the displacement volume varying means  
12a and 12b of the hydraulic pumps 3a and 3b respectively  
in the same process as described by referring to the  
embodiment shown in Fig. 1, so that the delivery by  
the hydraulic pumps is varied by following up the  
20 amount of operation of the pilot valves 18A and 18B.  
At this time, when the pistons of the control valves  
13a and 13b begin to move from neutral positions,  
pressure differential greater than the preload applied  
to the spring 56 or 57 in the pressure chambers 54 and  
25 55 respectively is generated between the pressure  
chambers 54 and 55, so that a pressure on the higher  
pressure side is supplied to the control valves 21a  
and 21b through the shuttle valves 22a and 22b and

1 change-over valves 23a and 23b. Thus the valves 21a  
and 21b are shifted to position B. Accordingly, when  
the hydraulic pumps 3a and 3b begin to deliver pressure  
fluid, the control valves 21a and 21b are already in  
5 position B to communicate the main lines 5a, 6a and  
5b, 6b with the main lines 8 and 9. In this way, the  
pressure fluid delivered by the pumps 3a and 3b is  
supplied to the hydraulic pumps 7a and 7b to drive same.

In the event that the prime mover 1a has  
10 its rpm reduced for some reason when the parts of the  
system are in the aforesaid condition, the rpm of the  
hydraulic pirot pump 4a connected to the prime mover  
1a also decreases and the pressure in the line 40a  
drops. A drop in the pressure in the line 40a enables  
15 the change-over valve 23a to return to normal position  
A, thereby releasing pressure fluid from the line  
51a. Release of pressure fluid from the line 51a  
enables the control valve 21a to return to position A  
as shown, so that the hydraulic pump 3a is shut by the  
20 control valve 21a off the other hydraulic pump 3b  
and the hydraulic motors 7a and 7b. Thus the other  
hydraulic pump is prevented from supplying pressure  
fluid to the hydraulic pump 3a connected to the prime  
mover 1a having its rpm reduced to an inordinately  
25 low level or shut down, so that the hydraulic pump  
3a is kept from acting as a motor.

As afore-mentioned, in case the prime movers  
1a and 1b are normally operating, the hydraulic pumps

1 3a and 3b deliver pressure fluid at a flow rate com-  
mensurate with the amount of operation of the pilot  
valve 18A or 18B, to thereby drive the hydraulic  
motors 7a and 7b respectively. Upon the pilot valve  
5 being returned to a neutral position to shut down the  
hydraulic pumps 3a and 3b and the load 11, the pistons  
of the hydraulic cylinders 13a and 13b are moved by  
the servo valves 14a and 14b toward a neutral position  
to also move the displacement volume varying means 12a  
10 and 12b of the hydraulic pumps 3a and 3b respectively  
to a neutral position, thereby reducing the flow rate  
of pressure fluid delivered by the pumps. When the  
load 11 has high inertia, the pressure on the suction  
side of the pumps rises as the flow rate of pressure  
15 fluid delivered by the pumps decreases, and the high  
pressure on the suction side acts on the cut-off valves  
15a and 15b through the shuttle valves 16a and 16b,  
to thereby switch the cut-off valves 15a and 15b to  
position B. This keeps the pistons of the control  
20 cylinders 13a and 13b from moving, and the flow rate  
of pressure fluid delivered by the hydraulic pumps  
3a and 3b gradually drops while the pressure in the  
main lines is being controlled to a level below the  
level at which the cut-off valves 15a and 15b are  
25 set to be switched, until reaching zero (0). When  
the flow rate of pressure fluid delivered by the  
hydraulic pumps reaches zero (0) or when the pistons  
of the control cylinders 13a and 13b reach a neutral

1 position, the pressure in the lines 48a, 49a, 48b and  
49b communicated with the pressure chambers of the control  
cylinders 13a and 13b is at a low level, so that the  
pilot pressure applied to the control valves 21a and  
5 21b is at a low level, to allow the valves 21a and 2b  
to return to normal position A. Thus even if the  
prime movers 1a and 1b are normally operating, the  
hydraulic motors are shut off the hydraulic pumps  
when the flow rate of pressure fluid delivered by  
10 the hydraulic pumps becomes zero (0) or the hydraulic  
motors 7a and 7b stop rotating. This permits the  
hydraulic motors to be kept stopped irrespective of  
an external force exerted thereon.

In the embodiment shown in Fig. 2 too, it  
15 is possible, when one of the prime movers is not in  
normal operation, such as when it is shut down, to  
return the control valve 21a or 21b to normal position  
A and to shut the hydraulic pump connected to the  
disabled prime mover off the other hydraulic pump and  
20 hydraulic motors. Additionally, in the embodiment  
shown in Fig. 2, it is possible, when the flow rate of  
pressure fluid delivered by the hydraulic pumps is zero  
(0), to close the ends of the main lines connected to  
the hydraulic motors, so as to thereby positively  
25 keep the hydraulic motors stopped.

In the embodiments shown in Figs. 1 and 2,  
one of the four-port, two-position directional control  
valves 21a and 21b is used as means for shutting one

1 of the hydraulic pumps off the other hydraulic pump  
and hydraulic motors. It is to be understood that the  
invention is not limited to this specific form of the  
embodiments and that modifications may be made thereto  
5 within the scope of the invention. Figs. 4 and 5 show  
modifications to the directional control valve 21a of  
the embodiment shown in Fig. 2. In Fig. 4, a four-  
port, two-position valve 21a' provided with no internal  
bypass passage is used, and a bypass passage 70 mounting  
10 a shut-off valve 71 connects the main lines 5a and 6a  
together. The valves 21a' and 71 are simultaneously  
switched by the pressure in a line 51a' corresponding  
to the line 51a shown in Fig. 2. In Fig. 5, two shut-off  
valves 21a" are used in place of the single control  
15 valve 21a'. The modifications shown in Figs. 4 and 5  
perform the same operation as the embodiment shown in  
Fig. 2.

Fig. 6 shows still another embodiment of the  
invention in which solenoid-operated valves 24a and 24b  
20 are used in place of the pilot-operated valves 21a  
and 21b shown in Figs. 1 and 2, and the supply of  
pressure fluid to the control cylinders 13a and 13b  
for controlling the displacement volume varying means  
12a and 12b of the hydraulic pumps 3a and 3b respectively  
25 is controlled by operating valves 25a and 25b which in  
turn are electrically controlled.

Pressures P5a, P6a, P5b and P6b in the main  
lines 5a, 6a, 5b and 6b are sensed by pressure sensors

1 26a, 27a, 26b and 27b respectively. Displacements X  
and X' of the displacement volume varying means 12a  
and 12b from the neutral position are sensed by displace-  
ment sensors 28a and 28b respectively. RPMs N and N'  
5 of the prime movers 1a and 1b are sensed by RPM sensors  
29a and 29b respectively. The signals produced by those  
sensors and a signal representing a manipulated variable  
 $X_L$  of an operating lever 30 from the neutral position  
are inputted to an arithmetic unit 31 which does  
10 necessary calculations and supplies control signals  
to an output device 32. Upon receipt of the control  
signals, the output device 32 supplies commands to the  
directional control valves 24a and 24b and the operating  
valves 25a and 25b, to effect control of these valves.  
15 The arithmetic unit 31 can operate by using  
an ordinary arithmetic circuit. However, the arithmetic  
unit 31 will be described as being used with a micro-  
computer and its operation will be described by  
referring to a flow chart shown in Fig. 7. The  
20 description only refers to the prime mover 1a, and it  
is to be understood that the prime mover 1b operates  
in the same manner as the prime mover 1a. It is also  
to be understood that when the value of X is positive,  
pump 3a delivers pressure fluid to the main line 5a  
25 and when it is negative, pump 3a delivers pressure  
fluid to the main line 5b.

In step S1, data  $X_L$ , P5a, P6a, X and N are  
read in. In step S2, it is determined whether or not



1 the RPM N of the prime mover is greater than a  
predetermined set value close to zero (0) or whether  
or not the prime mover is rotating normally. If the  
rotation is not normal, then the process proceeds to  
5 step S3 in which a displacement command Y to be  
supplied to the displacement volume varying means 12a  
is determined to  $Y = 0$ . In step S4, a command is  
given to the output device 32 to supply a command  
signal  $Y - X (= -X)$  to the operating valve 25a to  
10 render the displacement X of the varying means 12a  
zero (0) or to render the displacement volume zero  
(0) and to supply a command signal "close" to the  
directional control valve 24a to shift same to position  
A.

15 When the prime mover 1a is normally rotating,  
the process proceeds from step S2 to step S5 in which  
it is determined whether or not the manipulated variable  
 $X_L$  of the lever 30 is essentially zero (0). When  $X_L$   
is zero (0), the process proceeds to step S6; when not  
20 zero (0), the process proceeds to step S7. In step S6,  
it is determined whether or not the displacement X  
is essentially zero (0). When X is essentially zero  
(0), the process proceeds to step S3 and then to step  
S4. When X is not essentially zero (0), the process  
25 proceeds to step S7.

In step S7, it is determined whether or not  
the value of  $|X_L - X|$  is below an insensitive zone  
level  $\epsilon$ . When it is equal to or below  $\epsilon$ , the process

1 proceeds to step S8 in which it is determined whether  
or not the main line pressures P5a and P6a are higher  
than preset values. When they are below the preset  
values, the process proceeds to step S9 in which a  
5 displacement command Y is determined to  $Y = X$  to hold  
the present value of displacement X as it is. Then,  
the process proceeds to step S10. In step S10, a  
command is given to the output device 32 to supply  
a command signal  $Y - X (=0)$  to the operating valve  
10 25a and to supply a command signal "open" to the  
directional control valve 24a to shift same to position  
B.

When  $|X_L - X|$  is higher than the insensitive  
zone level  $\epsilon$  or when the main line pressures P5a and  
15 P6a are higher than the set values, the process proceeds  
to step S11, in which it is determined whether or not  
 $X_L - X$  is larger than zero (0). When  $X_L - X > 0$ , an  
increment  $\Delta Y$  corresponding to the main line pressure  
P5a is read out of the functional relation shown in  
20 Fig. 8 which is set previously. In Fig. 8, functions  
are preset in such a manner that even if the flow rate  
of the pressure fluid delivered by the pump 3a is  
varied by displacing by  $\Delta Y$  the displacement volume  
varying means 12a, a predetermined allowable highest  
25 pressure is not exceeded by the main line pressure  
P5a or P6a. In step S13, the displacement command Y  
is determined to  $Y = X + \Delta Y$ , and then in step S10 a  
command is given to the output device 32 to supply

1 a command signal to the operating valve 25a to increase  
the displacement X by  $\Delta Y$  and to supply a command  
signal "open" to the directional control valve 24a.

When  $X_L - X \leq 0$ , in step S14, a decrement  
5  $-\Delta Y$  of the displacement command Y which would not  
cause the main line pressure P6a to exceed the pre-  
determined allowable highest pressure is read out of  
the functional relation shown in Fig. 8. In step S15,  
the displacement command Y is determined to  $Y = X - \Delta Y$ ,  
10 and in step S10, a command is given to the output device  
32 to supply a command signal  $Y - X (= -\Delta Y)$  to the  
operating valve 25a, to decrease the displacement X  
by  $\Delta Y$  and to supply a command signal "open" to the  
direction control valve 24a.

15 The process described hereinabove is repeated.  
When the prime movers 1a and 1b are normally rotating  
and the manipulated variable  $X_L$  of the operating lever  
30 is not zero (0) or the operating lever 30 is not  
in a neutral position, the varying means 12a and 12b  
20 are shifted until their displacement agrees with the  
manipulated variable  $X_L$ . While the means 12a and 12b  
are being shifted, the internal pressures of the main  
lines 5a, 6a, 5b and 6b are kept below the predetermined  
allowable values. In the event that the prime mover  
25 1a or 1b shifts from the normal operation condition  
to an abnormal operating condition, the directional  
control valves 24a and 24b are switched to shutting  
position A. Thus the hydraulic pump 3a or 3b connected

1 to the prime mover 1a or 1b not in normal operating  
condition is shut off the other hydraulic pump and  
prevented from being forcedly rotated by the pressure  
fluid delivered by the other hydraulic pump. At the  
5 same time, a signal to return the varying means 12a  
or 12b to a neutral position is supplied to the operating  
valve 25a or 25b associated with the prime mover not  
in normal operating condition, so that the varying  
means 12a or 12b is returned to a neutral position  
10 and stops. In this connection, attention should be  
directed to the fact that in this embodiment a pressure  
signal supplied to the operating valves 25a and 25b  
is given from the line 41 interposed between the check  
valves 17a and 17b, so that even after one of the  
15 pilot pumps 4a or 4b has stopped rotating, a pressure  
of a predetermined adjusted value is supplied to both  
valves 25a and 25b. When the operating lever 30 is  
in the neutral position and the flow rate of the  
pressure fluid delivered by the hydraulic pumps 3a and  
20 3b is essentially zero (0), the directional control  
valves 24a and 24b are moved to shutting position A  
to ensure that the hydraulic motors 7a and 7b are  
held in shutdown position against an external position,  
even if the prime movers 1a and 1b are normally rotating.  
25 In the embodiment shown in Fig. 6, revolution  
meters 29a and 29b are used as means for sensing whether  
or not the prime movers 1a and 1b are in normal operating  
condition. However, the invention is not

1 limited to this specific form of rotation condition  
sensing means and any other suitable known means, such  
as means for sensing the output pressure of a prime  
mover lubricant supply pump, means for sensing the  
5 output current of a generator driven by the prime movers,  
etc. The aim of sensing that the flow rate of the  
pressure fluid delivered by the variable displacement  
hydraulic pumps 3a and 3b and the command thereto have  
become essentially zero (0) can be attained by sensing  
10 both a control pressure linked to the operating lever  
and a control pressure associated with the flow rate  
of the pressure fluid delivered by the pump, such as  
an output pressure of the neutral position detecting  
port formed in the servo valve or an output side pressure  
15 of the cut-off valve.

While preferred embodiments of the invention  
have been described using specific terms, such description  
is for illustrative purposes only, and it is to be  
understood that changes and variations may be made  
20 without departing from the spirit or scope of the  
following claims.

WHAT IS CLAIMED IS:

1. A hydraulic drive system including at least one hydraulic actuator, a plurality of variable displacement hydraulic pumps, each of said hydraulic pumps being connected to said hydraulic actuator in a manner to form a closed hydraulic circuit therewith and said hydraulic pumps being connected in parallel with each other, and a plurality of prime movers each connected to one of said plurality of hydraulic pumps to drive same, characterized by:

valve means (21a, 21b, 24a, 24b) each associated with one of said hydraulic pumps (3a, 3b) to fluidly and selectively shut the hydraulic pump associated therewith off said hydraulic actuator and the other hydraulic pump; and

control means each associated with one of said prime movers (1a, 1b) to control said valve means (21a, 21b, 24a, 24b) in accordance with the operating condition of the prime mover in such a manner that when the prime mover is not in normal operating condition, the hydraulic pump connected to the prime mover not normally operating is fluidly shut off said hydraulic actuator and the other hydraulic pump.

2. A hydraulic drive system as claimed in claim 1, wherein said valve means each comprise a two-position directional control valve (21a, 21b, 24a, 24b) formed with two input ports communicating with one of the hydraulic pumps (3a, 3b) and two output ports

communicating with the actuator (7a, 7b), said  
two-position directional control valve (21a, 21b, 24a,  
24b) being movable between a first position (A) in which  
the two input ports are brought into communication with  
5 each other and the two output ports are shut off each  
other and a second position (B) in which the two input  
ports and the two output ports are connected to each  
other.

3. A hydraulic drive system as claimed in claim  
10 2, wherein said two-position directional control valve  
comprises a pilot-operated valve (21a, 21b) normally  
disposed in the first position (A), and wherein said  
control means each comprise a hydraulic pilot pump (4a,  
4b) driven by the prime mover (1a, 1b), and conduit  
15 means (47a, 47b) to cause a pressure fluid delivered by  
said pilot pump (4a, 4b) to act on the directional control  
valve (21a, 21b) in a manner to shift same to the  
second position (B).

4. A hydraulic drive system as claimed in claim  
20 2, wherein said two-position directional control valve  
(24a, 24b) comprises a solenoid-operated valve normal-  
ly disposed in the first position (A), including a  
solenoid energized when the prime mover (1a, 1b) is  
normal operating condition.

25 5. A hydraulic drive system as claimed in claim  
4, wherein said control means each comprise means  
(29a, 29b) for sensing the number of revolutions of  
the prime mover (1a, 1b), means (31) for determining

whether the sensed number of revolutions is greater or smaller than a predetermined set value, and means (32) for energizing the solenoid of the directional control valve (24a, 24b) when the sensed number of revolutions  
5 is greater than the set value.

6. A hydraulic drive system as claimed in claim 1, wherein said control means for said valve means each comprise additional means operative to control said valve means in response to the flow rate of pressure  
10 fluid delivered by the hydraulic pump, to thereby fluidly shut the hydraulic pump off said hydraulic actuator and the other hydraulic pump when the flow rate of pressure fluid delivered by the hydraulic pump is essentially zero (0).

15 7. A hydraulic drive system as claimed in claim 6, wherein said valve means each comprise a two-position directional control valve (21a, 21b, 24a, 24b) formed with two input ports communicating with one of the hydraulic pumps (3a, 3b) and two output ports  
20 communicating with the actuator (7a, 7b), said two-position directional control valve (21a, 21b, 24a, 24b) being movable between a first position (A) in which the two input ports are brought into communication with each other and the two output ports are shut off  
25 each other and a second position (B) in which the two input ports and the two output ports are connected to each other.

8. A hydraulic drive system as claimed in claim 7,



wherein said directional control valve comprises a pilot-operated valve (21a, 21b) normally disposed in the first position (A), and wherein said control means each comprise a hydraulic pilot pump (4a, 4b) driven by said prime mover (1a, 1b), a shuttle valve (22a, 22b) communicating with opposite two pressure chambers (54, 55) of a control cylinder (13a, 13b) which is provided to drive displacement volume adjusting means (12a, 12b) for the hydraulic pump (3a, 3b), first conduit means (50a, 51a or 50b, 51b) supplying an output of said shuttle valve (22a, 22b) to the pilot-operated directional control valve (21a, 21b) as a pilot pressure, a pilot-operated two-position change-over valve (23a, 23b) mounted in said first conduit means and movable between a first position (A) in which the directional control valve (21a, 21b) has a pilot pressure released therefrom and a second position (B) in which said shuttle valve (22a or 22b) is brought into communication with the directional control valve (21a or 21b), and second conduit means (52a or 52b) for supplying pressure fluid delivered by said pilot pump (4a, 4b) to said change-over valve (23a, 23b) as a pilot pressure.

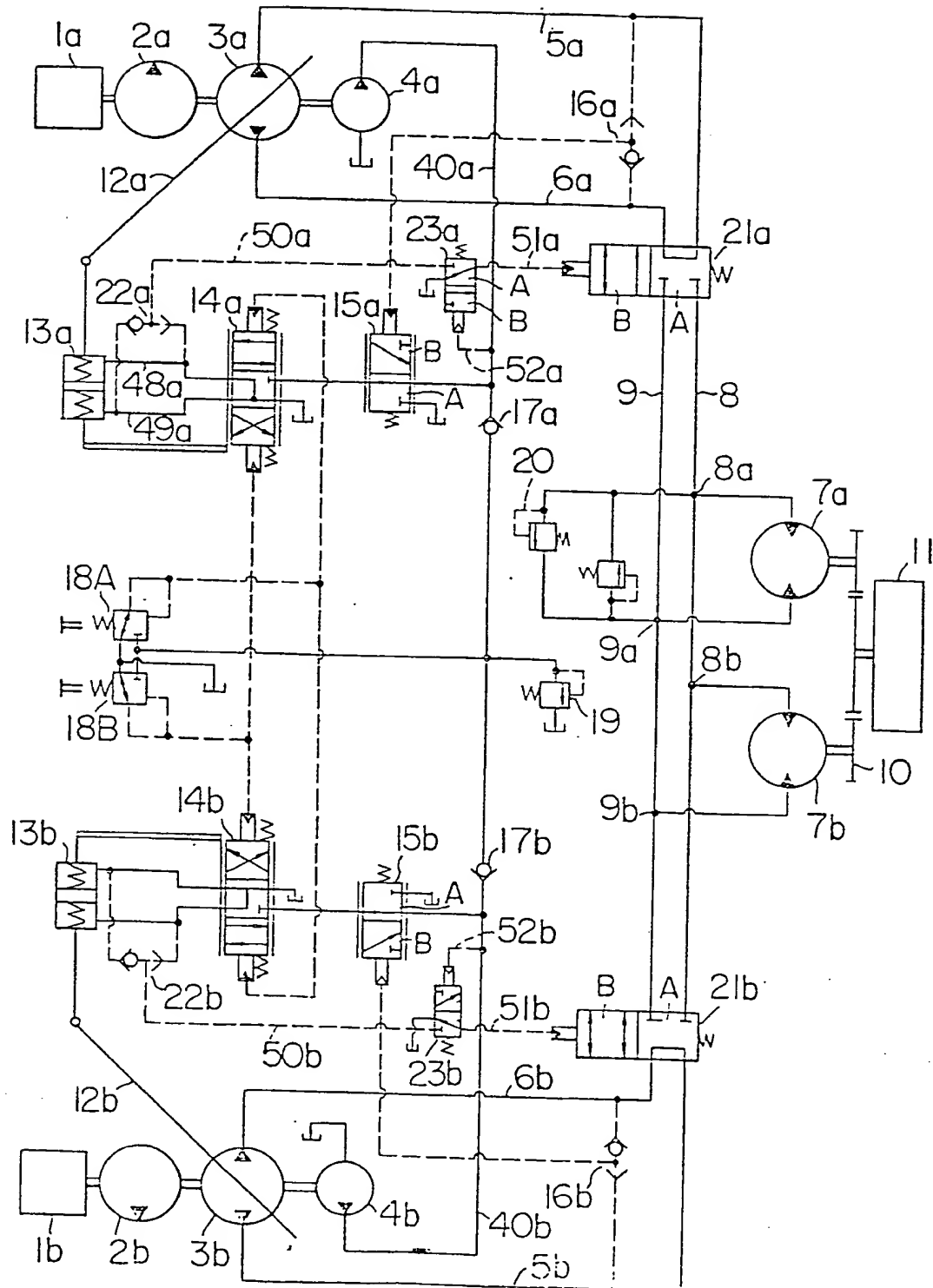
9. A hydraulic drive system as claimed in claim 6, further comprising a bypass passage (70) connecting together two main lines (5a, 6a, 5b, 6b) connected to two ports of each said hydraulic pump (3a, 3b), and an additional shut-off valve (71) for opening and blocking said bypass passage (70), said additional

shut-off valve (71) being operatively connected to said valve means.

10. A hydraulic drive system as claimed in claim 7, wherein said directional control valve is a solenoid-  
5 operated valve (24a, 24b) normally disposed in the first position (A), and wherein said control means each comprise means (29a, 29b) for sensing the number of revolutions of the prime mover (1a, 1b), first means (31) for sensing whether the sensed number of revolutions  
10 is greater or smaller than a predetermined set value, second means (31) for determining whether or not the flow rate of pressure fluid delivered by the hydraulic pump (3a or 3b) and the command value given thereto are both essentially zero (0), and means (32) responsive to  
15 said first means and said second means to energize said solenoid-operated valve (24a, 24b) when the sensed number of revolutions is greater than the predetermined set value and the flow rate of pressure fluid delivered by the hydraulic pump and the command value given  
20 thereto are not essentially zero (0).

The schematic diagram illustrates a hydraulic system for a vehicle seat, divided into two parallel sections labeled 'a' and 'b'. Each section contains a pump (1a, 1b), a check valve (2a, 2b), a pressure relief valve (3a, 3b), a solenoid valve (4a, 4b), a flow control valve (6a, 6b), and a directional control valve (7a, 7b). The system also includes a central manifold (10) and a reservoir (11). Various ports and connections are labeled throughout the diagram.

FIG. 2



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FIG. 3

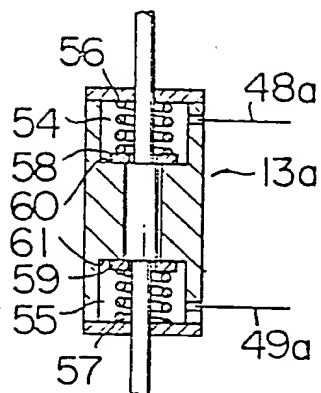


FIG. 4

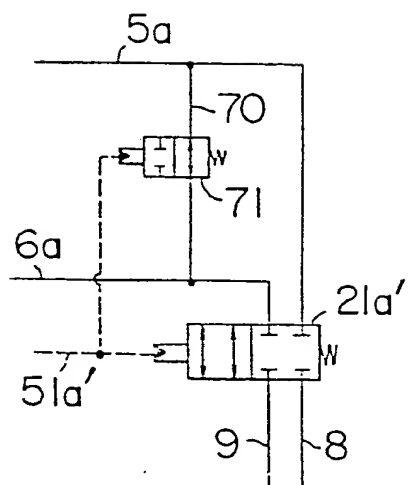


FIG. 5

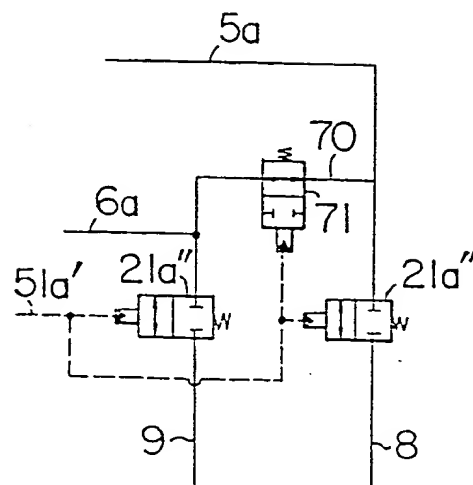


FIG. 8

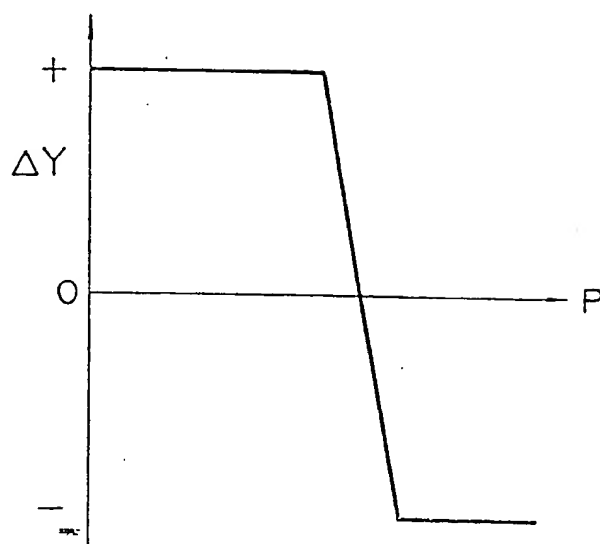
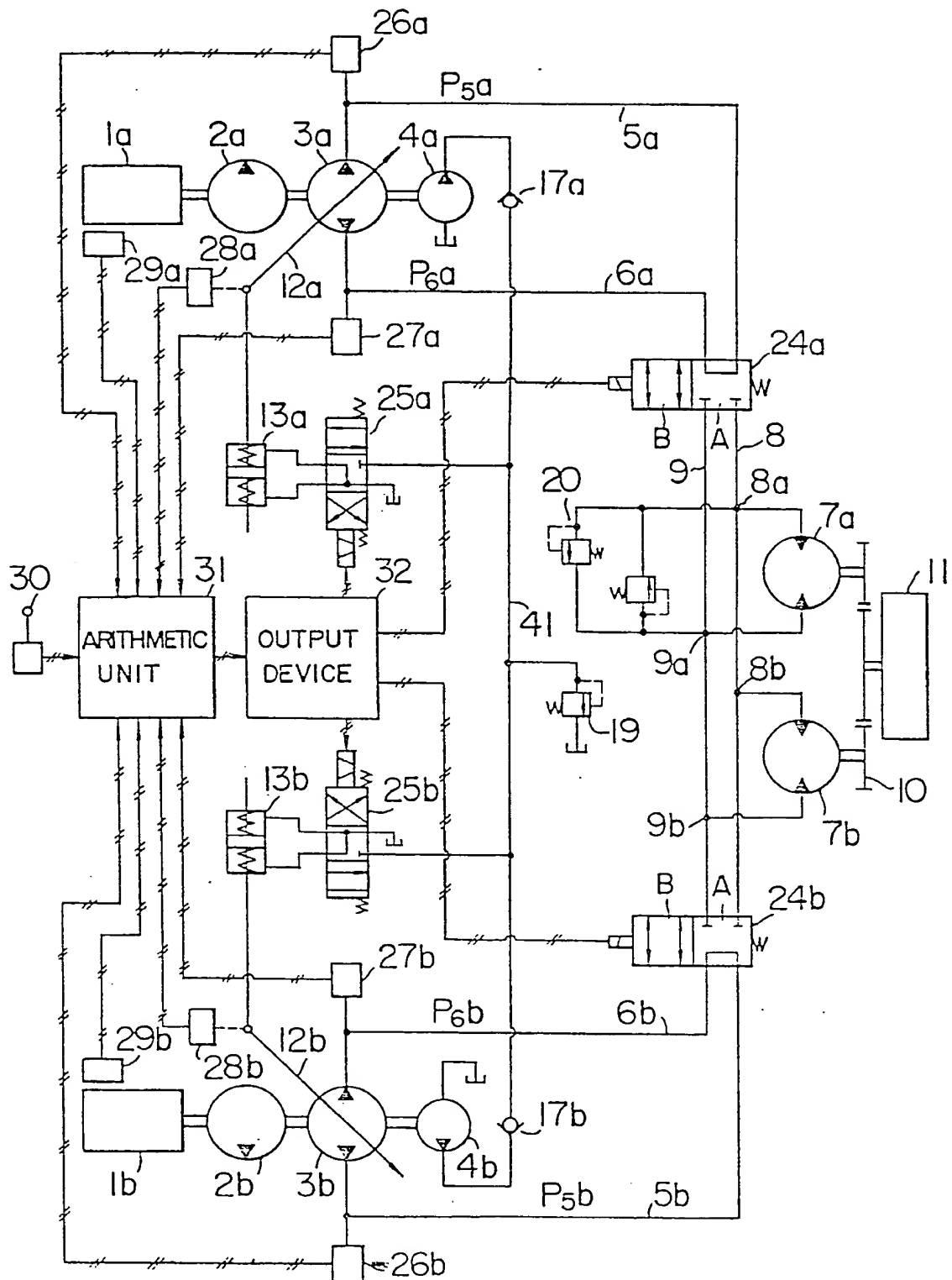


FIG. 6



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FIG. 7

